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FIG. 1

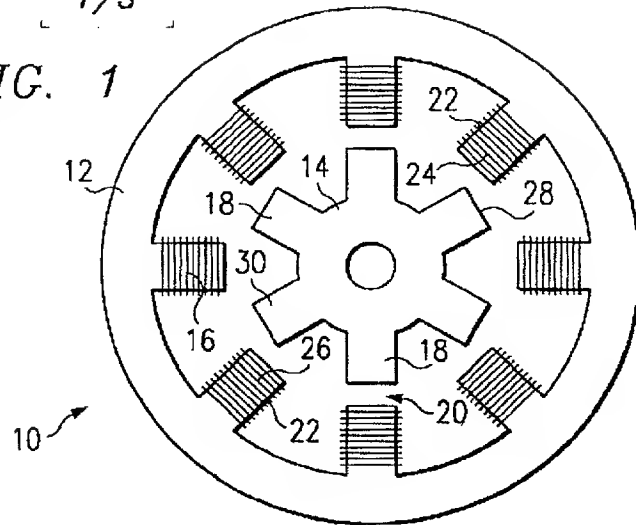


FIG. 2

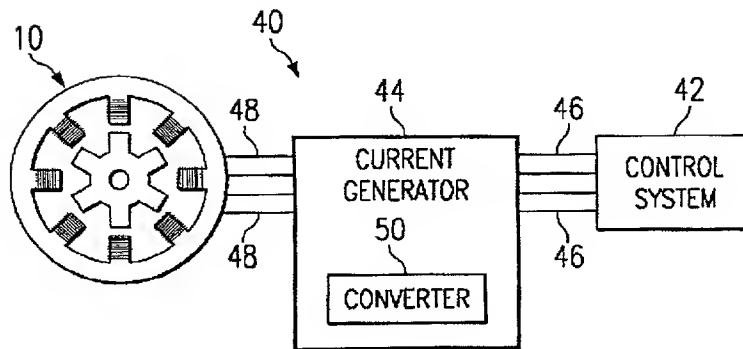
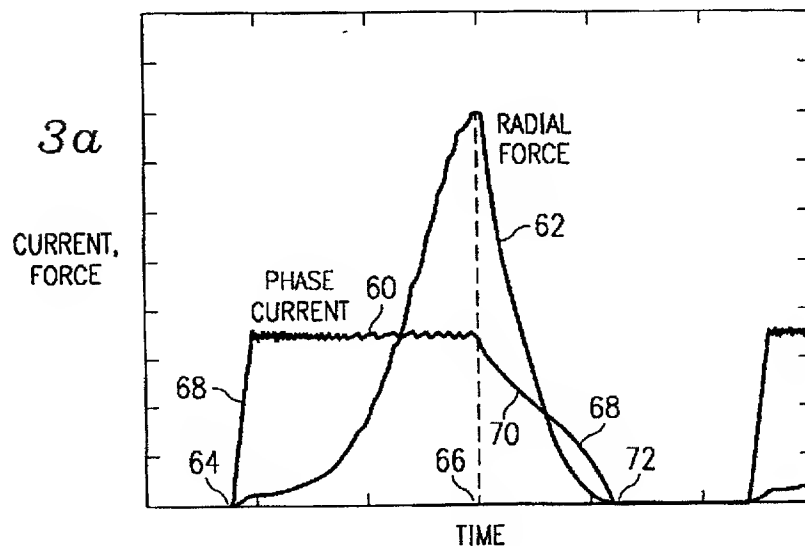


FIG. 3a



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FIG. 3b

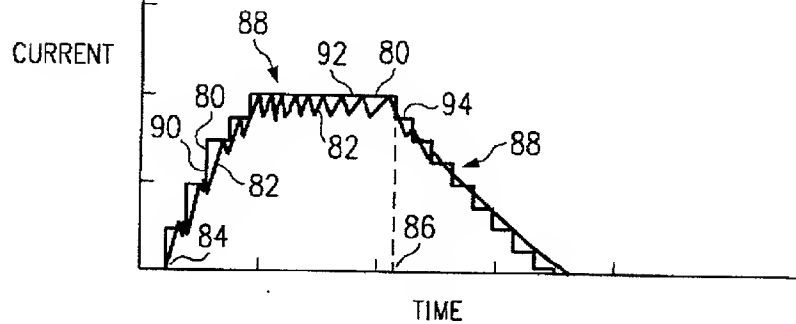


FIG. 4

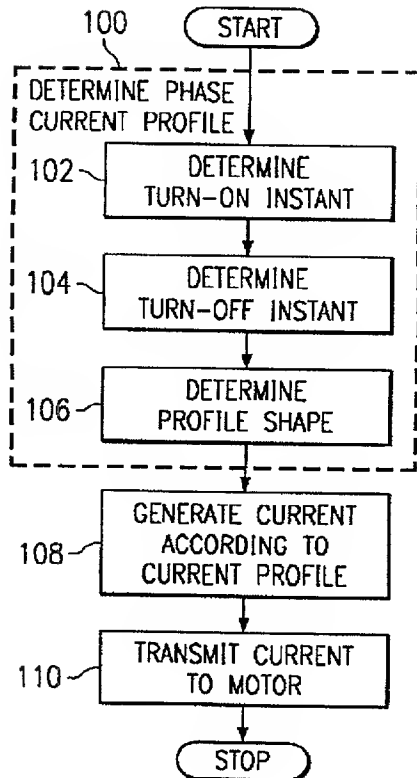
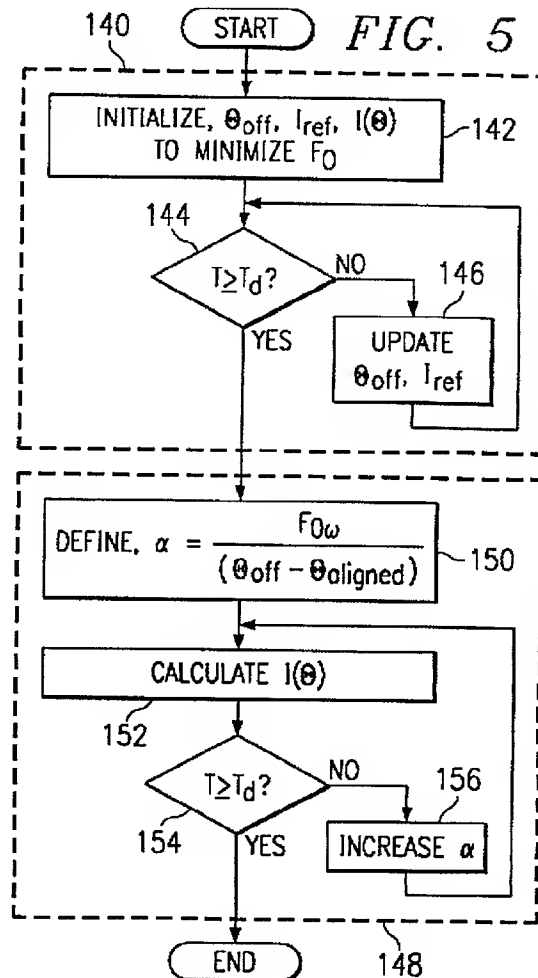


FIG. 5



```
graph TD; START([START]) --> 230[230 RUN MOTOR]; 230 --> 232[232 MEASURE INPUTS: TORQUE, SPEED, ANGLE]; 232 --> 234[234 MEASURE OUTPUT: CURRENT PROFILE]; 234 --> 236[236 ADJUST NEURAL NETWORK WEIGHTS]; 236 --> STOP([STOP]); 236 --> 230;
```

The flowchart illustrates a control system process. It begins with a 'START' terminal, leading to a process block '230 RUN MOTOR'. This is followed by '232 MEASURE INPUTS: TORQUE, SPEED, ANGLE', then '234 MEASURE OUTPUT: CURRENT PROFILE', and '236 ADJUST NEURAL NETWORK WEIGHTS'. A feedback loop connects the end of block 236 back to the input of block 230. The process concludes at a 'STOP' terminal.

```
graph TD; START([START]) --> RUN_MOTOR[250 RUN MOTOR]; RUN_MOTOR --> RECEIVE_INPUTS[252 RECEIVE INPUTS: TORQUE, SPEED, ANGLE]; RECEIVE_INPUTS --> GENERATE_CURRENT[254 GENERATE CURRENT PROFILE USING NEURAL NETWORK]; GENERATE_CURRENT --> STOP([STOP]); GENERATE_CURRENT --> RUN_MOTOR;
```

The flowchart illustrates the control system process. It begins with a 'START' terminal, leading to a process block '250 RUN MOTOR'. This is followed by '252 RECEIVE INPUTS: TORQUE, SPEED, ANGLE', then '254 GENERATE CURRENT PROFILE USING NEURAL NETWORK'. From this block, the process loops back to '250 RUN MOTOR' and eventually reaches a 'STOP' terminal.